

LISTING OF THE CLAIMS

This listing of claims will replace all prior versions, and listings, of claims in the application:

Listing of Claims:

What is claimed is:

- 1 1. (Original) A robot, comprising:
2 a mobile holonomic platform;
3 a camera coupled to said mobile holonomic platform;
4 an arm coupled to said mobile holonomic platform; and,
5 a first grasper coupled to said arm.
- 1 2. (Original) The robot of claim 1, further comprising a monitor coupled to
2 said mobile holonomic platform.
- 1 3. (Original) The robot of claim 1, wherein further comprising a shoulder
2 actuator coupled to said arm.
- 1 4. (Original) The robot of claim 1, wherein said arm has an elbow actuator.
- 1 5. (Original) The robot of claim 1, wherein said arm includes a first linkage,
2 and a second linkage coupled to said first linkage, said arm having an actuator that moves

3 said second linkage relative to said first linkage in a first degree a freedom in a first
4 mode, and in a second degree of freedom in a second mode.

1 6. (Original) The robot of claim 1, wherein said first grasper is coupled to a
2 wrist joint of said arm.

1 7. (Original) The robot of claim 1, further comprising a second grasper
2 coupled to said arm.

1 8. (Original) The robot of claim 5, wherein said first degree of freedom
2 pivots about an elbow axis and said second degree of freedom slides relative to the elbow
3 axis.

1 9. (Original) A robot, comprising:
2 a mobile holonomic platform;
3 a camera coupled to said mobile holonomic platform;
4 an arm coupled to said mobile holonomic platform; and,
5 first grasper means for grasping an object.

1 10. (Original) The robot of claim 9, further comprising a monitor coupled to
2 said mobile holonomic platform.

1 11. (Original) The robot of claim 9, wherein further comprising a shoulder
2 actuator coupled to said arm.

1 12. (Original) The robot of claim 9, wherein said arm has an elbow actuator.

1 13. (Original) The robot of claim 9, wherein said arm includes a first linkage,
2 and a second linkage coupled to said first linkage, said arm having actuator means for
3 moving said second linkage relative to said first linkage in a first degree a freedom in a
4 first mode, and in a second degree of freedom in a second mode.

1 14. (Original) The robot of claim 9, wherein said first grasper means is
2 coupled to a wrist joint of said arm.

1 15. (Original) The robot of claim 9, further comprising second grasper means
2 for grasping the object.

1 16. (Original) The robot of claim 13, wherein said first degree of freedom
2 pivots about an elbow axis and said second degree of freedom slides relative to the elbow
3 axis.

1 17. (Original) A method for operating a robot, comprising:
2 moving a mobile holonomic platform that is coupled to an arm;
3 moving an arm coupled to the mobile holonomic platform; and,
4 actuating a first grasper to grasp an object.

1 18. (Original) The method of claim 17, further comprising grasping and
2 moving a wheelchair.

1 19. (Original) The method of claim 17, further comprising capturing an image
2 in a camera that is coupled to the mobile holonomic platform.

1 20. (Original) The method of claim 17, further comprising displaying an
2 image on a monitor coupled to the mobile holonomic platform.

1 21. (Original) A robot system, comprising:
2 a broadband network;
3 a remote station coupled to said broadband network, said remote station having a
4 handle that can be manipulated to generate movement signals that are transmitted through
5 said broadband network;
6 a robot that is coupled to said broadband network and receives said movement
7 signals from said handle of said remote station, said robot including;
8 a mobile holonomic platform;
9 a camera coupled to said mobile holonomic platform;
10 an arm coupled to said mobile holonomic platform; and,
11 a first grasper coupled to said arm.

1 22. (Original) The robot system of claim 21, further comprising a monitor
2 coupled to said mobile holonomic platform.

1 23. (Original) The robot system of claim 21, wherein further comprising a
2 shoulder actuator coupled to said arm.

1 24. (Original) The robot system of claim 21, wherein said arm has an elbow
2 actuator.

1 25. (Original) The robot system of claim 21, wherein, said arm includes a first
2 linkage, and a second linkage coupled to said first linkage, said arm further having an
3 actuator that moves said second linkage relative to said first linkage in a first degree a
4 freedom in a first mode, and in a second degree of freedom in a second mode in response
5 to said movement signals.

1 26. (Original) The robot system of claim 21, wherein said first grasper is
2 coupled to a wrist joint of said arm.

1 27. (Original) The robot system of claim 21, further comprising a second
2 grasper coupled to said arm.

1 28. (Original) The robot system of claim 25, wherein said first degree of
2 freedom pivots about an elbow axis and said second degree of freedom slides relative to
3 the elbow axis.

1 29. (Original) A robot system, comprising:
2 a broadband network;
3 input means for generating movement signals and transmitting said movement
4 signals through said broadband network;

5 a robot that is coupled to said broadband network and receives said movement
6 signals of said input means, said robot including;
7 a mobile holonomic platform;
8 a camera coupled to said mobile holonomic platform;
9 an arm coupled to said mobile holonomic platform; and,
10 first grasper means for grasping an object.

1 30. (Original) The robot system of claim 29, further comprising a monitor
2 coupled to said mobile holonomic platform.

1 31. (Original) The robot system of claim 29, wherein further comprising a
2 shoulder actuator coupled to said arm.

1 32. (Original) The robot system of claim 29, wherein said arm has an elbow
2 actuator.

1 33. (Original) The robot system of claim 29, wherein, said arm includes a first
2 linkage, and a second linkage coupled to said first linkage, said arm further having
3 actuator means for moving said second linkage relative to said first linkage in a first
4 degree a freedom in a first mode, and a second degree of freedom in a second mode in
5 response to said movement signals.

1 34. (Original) The robot system of claim 29, wherein said first grasper means
2 is coupled to a wrist joint of said arm.

1 35. (Original) The robot system of claim 29, further comprising second
2 grasper means for grasping the object.

1 36. (Original) The robot system of claim 33, wherein said first degree of
2 freedom pivots about an elbow axis and said second degree of freedom slides relative to
3 the elbow axis.

1 37. (Original) A method for operating a robot, comprising:
2 generating a platform movement command;
3 transmitting the platform movement command through a broadband network;
4 moving a mobile holonomic platform that is coupled to an arm in response to the
5 transmitted movement command;
6 generating a first arm movement command;
7 transmitting the first arm movement command through the broadband network;
8 moving the arm in response to the first arm movement command;
9 generating a first grasper command;
10 transmitting the first grasper command through the broadband network; and,
11 actuating a first grasper in accordance with the first grasper command.

1 38. (Original) The method of claim 37, further comprising grasping and
2 moving a wheelchair.

1 39. (Original) The method of claim 37, further comprising capturing an image
2 in a camera that is coupled to the mobile holonomic platform.

1 40. (Original) The method of claim 37, further comprising displaying an
2 image on a monitor coupled to the mobile holonomic platform.